CHAPTER V
CONCLUSIONS AND SUGGESTIONS

5.1 CONCLUSIONS

After testing the styrofoam using a robotic arm, the conclusion is:

1. Articulated robotic arm configuration is obtained with series arrangement on double head servo motors and mega arduino controllers.

2. Arm robot that has been made can move automatically after inputting some position from the motor.

3. Errors that occur in the cutting process are caused by several factors, namely the additional movement of the servo motor, the structure of the robot frame is not sturdy, and styrofoam improper placement.

5.2 Suggestions

Based on the results of the research that has been done, it can be suggested for further research:

1. The programs need to calibate to get the same result with actual angle
2. Better accuracy motor is needed in making the program suitable for the movement of the robot arm.
3. The chosen robot frame structure must be sturder.
4. Placement of styrofoam is done more thoroughly.